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<input type="checkbox"/>	L3	bacchi.in.	165
<input type="checkbox"/>	L2	yim.in. and robot and substrate	8
<input type="checkbox"/>	L1	10/697731	1

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Key: IEEE JNL = IEEE Journal or Magazine, IEE JNL = IEE Journal or Magazine, IEEE CNF = IEEE Conference, IEE CNF = IEE Conference, IEEE STD = IEEE Standard

1. On covariances for fusing laser rangars and vision with sensors onboard a moving robot

Nygards, J.; Wernersson, A.;
Intelligent Robots and Systems, 1998. Proceedings., 1998 IEEE/RSJ
International Conference on
Volume 2, 13-17 Oct. 1998 Page(s):1053 - 1059 vol.2
IEEE CNF

2. A simulation environment to test fuzzy navigation strategies based on perceptions

Garcia-Perez, L.; Garcia-Alegre, M.C.;
Fuzzy Systems, 2001. The 10th IEEE International Conference on
Volume 2, 2-5 Dec. 2001 Page(s):590 - 593 vol.3
IEEE CNF

3. Localizing mobile RF targets using multiple unmanned aerial vehicles with heterogeneous sensing capabilities

Pack, D.; York, G.; Toussaint, G.;
Networking, Sensing and Control, 2005. Proceedings. 2005 IEEE
19-22 March 2005 Page(s):632 - 637
IEEE CNF



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Key: IEEE JNL = IEEE Journal or Magazine, IEE JNL = IEE Journal or Magazine, IEEE CNF = IEEE Conference, IEE CNF = IEE Conference, IEEE STD = IEEE Standard

1. Conceptual design of an integrated laser-optical measuring system for flexible manipulator

Xu, W.L.; Tso, S.K.; Wang, X.S.;
Systems, Man, and Cybernetics, 1996., IEEE International Conference on
Volume 2, 14-17 Oct. 1996 Page(s):1247 - 1252 vol.2

IEEE CNF

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[United States Patent Application: 0050096794](#)

the **robot** has at least one motor for manipulating a **linkage controlling** the ...
one **sensor onboard** the **robot** for providing **substrate support displacement** ...
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[Method and apparatus for monitoring the position of a ...](#)

... for manipulating a **linkage controlling** the **displacement** of a **substrate** ...
one **sensor onboard** the **robot** for providing **substrate support displacement** ...
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